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[PDF] ► Subacromial impingement syndrome: the effect of **changing posture** on shoulder range of ...

JS Lewis, C Wright, A Green - J Orthop Sports Phys Ther, 2005 - azpt.com

... assess **posture** and devise rehabilitation programs to **correct posture**, there is little ... pathology is associated with a high morbidity **rate**, with ... **Changing Posture** ...

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Design and control of a pendulum driven hopping robot- ► [kfupm.edu.sa](http://kfupm.edu.sa) [PDF]

F Iida, C Aul - Proc of the IEEE/RSJ International Conference on ..., 2002 - eprints.kfupm.edu.sa

... structure, the robot was able to **correct** its **posture** ... were then developed for straight **walk**- ing, reversing ... est is the investigation of different **gait** patterns. ...

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[PDF] ► Understanding Orbits

A Motion, M Weight, I Momentum, C Momentum ... - faa.gov

... at 1 m/s (about the speed of a brisk **walk**), we must ...  $p \Delta t$  ---- **change** in **momentum** **change** in time ... Thus, his model of gravity had been **correct** all along! ...

Related articles - View as HTML

**Gait** generating device of legged mobile robot and legged mobile robot controller

T Takenaka, T Matsumoto, T Yoshiike... - US Patent App. 10/561,988, 2004 - Google Patents

... BODY POSITION/ VELOCITY, INITIAL BODY **POSTURE** ANGLE/ANGULAR ... DETERMINE **GAIT** PARAMETERS

OF CURRENT TIME **GAIT**. S026 S028 SUBROUTINE FOR **CORRECTING** CURRENT TIME ...

All 6 versions

Controller of legged mobile robot

T Takenaka, T Matsumoto, T Yoshiike... - US Patent App. 10/562,327, 2004 - Google Patents

... **range**, then the motion of a desired **gait** is determined by **correcting** the provisional ... 60 90 80->, JOYSTICK f ISTCALCUATION UNIT **POSTURE** SENSOR [ A/D ...

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Human hamstring muscles adapt to eccentric exercise by **changing** optimum length.-

► [psu.edu](http://psu.edu) [PDF]

CL BROCKETT, DL MORGAN, UWE Proske - Medicine & Science in Sports & Exercise, 2001 - acsm-msse.org

... If our hypothesis is **correct**, such a measure would ... position while maintaining a rigid body **posture** to restrict ... After the exercise, there was a **change** in the ...

Cited by 111 - Related articles - BL Direct - All 7 versions

[PDF] ► ... plane characterization of normal human ankle function across a **range** of walking **gait** ...

ML Palmer - 2002 - Citeseer

... normal ankle function could also provide direction in **correcting** ... instructed to **walk** at that same self-selected speed ... flat to the time when the **gait** cycle begins ...

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Energy-saving mechanisms in walking and running- ► [biologists.org](http://biologists.org) [PDF]

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### Adjusting step length for rough terrain locomotion

JK Hodgins, MN Raibert - IEEE Transactions on Robotics and Automation, 1991 - [ieeexplore.ieee.org](http://ieeexplore.ieee.org)  
... to specify direction and speed of travel for **walking** on smooth ... This machine was able to **walk** up and down ... travels around a circle with a **running gait** that uses ...

Cited by 138 - Related articles - All 3 versions

### A running experiment of humanoid biped- ► [tistory.com](http://tistory.com) [PDF]

T Nagasaki, S Kajita, K Kaneko, K Yokoi, K ... - 2004 IEEE/RSJ International Conference on ... - [ieeexplore.ieee.org](http://ieeexplore.ieee.org)

... Most of them focus on biped **walk**- ing as an ... of '18 [kg] weight and could **run** at 1.25 ... prevent ordinary **humanoid** activities such as **walking**, carrying objects ...

Cited by 21 - Related articles - All 5 versions

### [PDF] ► Running in the real world: adjusting leg stiffness for different surfaces

DP Ferris, M Louie, CT Farley - Proceedings: Biological Sciences, 1998 - [pubmedcentral.nih.gov](http://pubmedcentral.nih.gov)

... to adjust leg stiffness allows humans to **run** similarly on ... PR 1979 The influence of track compliance on **running**. ... at different speeds of human **walking** and **running** ...

Cited by 94 - Related articles - View as HTML - BL Direct - All 15 versions

### Sky-hook suspension control of a quadruped walking vehicle

K Yoneda, H Iiyama, S Hirose - 1994 IEEE International Conference on Robotics and ..., 1994 - [ieeexplore.ieee.org](http://ieeexplore.ieee.org)

... A chart of foot forces indicates the **gait** includes 2-leg ... body were slightly larger than that of statically stable **walking**, TITAN VI could **walk** stably enough ...

Cited by 40 - Related articles - BL Direct

### Adaptive gait control of a biped robot based on realtime sensing of the ground profile

S Kajita, K Tani - Autonomous Robots, 1997 - Springer

... our biped **robot**, Meltran II, to **walk** over ground ... This paper discusses the adaptive **gait** control method of a ... the descriptions in this paper to **walking** on ground ...

Cited by 78 - Related articles - BL Direct - All 4 versions

### Evidence for spring loaded inverted pendulum running in a hexapod robot- ► [dlc.mit](http://dlc.mit) [PDF]

R Altendorfer, U Saranli, H Komsuoglu, D ... - Experimental robotics VII, 2001 - [books.google.com](http://books.google.com)

... plate while the **robot** performs an alternating tripod **gait**. ... established in [16] to distinguish **walking** from **running**. ... time as the data trajectory is **run** with the ...

Cited by 14 - Related articles - BL Direct - All 23 versions

### [PDF] ► Cheap" rapid locomotion of a quadruped robot: Self-stabilization of bounding gait

F Iida, R Pfeifer - Intelligent Autonomous Systems, 2004 - [people.csail.mit.edu](http://people.csail.mit.edu)

... a relatively complicated behavior of dynamic **walking** if it ... On the other hand, for the **run**- ning/hopping ... versa, which results in the stable **gait** over multiple ...

Cited by 22 - Related articles - View as HTML - All 2 versions

### Planning strategies for the ambler walking robot

D Wettergreen, H Thomas, C Thorpe - IEEE International Conference on Systems Engineering ..., 1990 - [ieeexplore.ieee.org](http://ieeexplore.ieee.org)

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**The development of Honda humanoid robot-** [snu.ac.kr](#) (PDF)

K Hirai, M Hirose, Y Haikawa, T Takenaka - 1998 IEEE International Conference on Robotics and ..., 1998 - [ieeexplore.ieee.org](#)

... the C-ATGRF to an appropriate position by **adjusting** each foot's ... In the previous example, the **Model** ZMP control ... the robot from maintaining the **desired** posture. ...

Cited by 986 - Related articles - BL Direct - All 5 versions

... dynamic **walking** of a quadruped **robot** on irregular terrain by using neural system **model**

H Kimura, Y Fukuoka, Y Hada, K Takase - IEEE/RSJ. Intelligent Robots and Systems, 2000 - Springer

... central pattern generator) and reflexes receiving **adjustment** signals from ... 2. Neural oscillator as a **model** of a CPG ... Adaptive Dynamic **Walking** of a Quadruped **Robot** ...

Cited by 81 - Related articles - BL Direct - All 4 versions

**Planning walking patterns for a biped robot-** [cmu.edu](#) (PDF)

Q Huang, K Yokoi, S Kajita, K Kaneko, H Arai, ... - IEEE Transactions on robotics and automation, 2001 - [ieeexplore.ieee.org](#)

... motion without first designing the **desired** ZMP trajectory ... Hodgins and MH Raibert, "Adjusting step length ... A theoretically motivated reduced order **model** for the ...

Cited by 288 - Related articles - BL Direct - All 16 versions

**Making feasible walking motion of humanoid robots from human motioncapture data**

A Dasgupta, Y Nakamura - 1999 IEEE International Conference on Robotics and ..., 1999 - [ieeexplore.ieee.org](#)

... suggested the use of hipper body motion **correction** for stabilizing a ... ground contact point, obtained from the foot **model** of Sec ... taken as the **desired** ZMP ...

Cited by 101 - Related articles - BL Direct - All 2 versions

**Adaptive dynamic walking of a quadruped robot on irregular terrain based on biological ...**

Y Fukuoka, H Kimura, AH Cohen - The International Journal of Robotics Research, 2003 - [ijr.sagepub.com](#)

... The neural system **model** consists of a central pattern ... The **desired** angle and P-gain of each joint in ... Takase Adaptive **Running** of a Quadruped **Robot** Using Forced ...

Cited by 209 - Related articles - BL Direct - All 2 versions

**Posture control of a cockroach-like robot**

GM Nelson, RD Quinn - 1998 IEEE International Conference on Robotics and ..., 1998 - [ieeexplore.ieee.org](#)

... ne represents a **desired** vertical load responsibility for each ... animals may "dwell" around this **model** even on rough terrain by **adjusting** body orientation. ...

Cited by 82 - Related articles - BL Direct - All 7 versions

[PDF] [►](#) **Stable control of a simulated one-legged running robot with hip and leg compliance**

M Ahmadi, M Buehler - IEEE Transactions on Robotics and Automation, 1997 - CiteSeer

... For this **model**, proper spring selection and initial conditions ... It also tracks changes in **desired robot** velocity and ... energy savings based on a **robot** design with ...

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**Dynamic walking control of a biped robot along a potential energyconserving orbit**

S Kajita, T Yamaura, A Kobayashi - IEEE Transactions on Robotics and Automation, 1992 - [ieeexplore.ieee.org](#)

... His **robot** could generate the **gait** pattern passively without ... of the trajectories of

an ideal biped **model**. ... realize the biped locomotion of **desired** velocity and ...

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### **Adjusting** step length for rough terrain locomotion

JK Hodgins, MN Raibert - IEEE Transactions on Robotics and Automation, 1991 - [ieeexplore.ieee.org](#)

... planning a path, selecting a foothold, and **adjusting** step length. ... cue occurred late

in the step, the **adjustment** was made ... trace for the body and a **model** of the ...

[Cited by 138](#) - [Related articles](#) - [All 3 versions](#)

### A robust layered control system for a mobile **robot**- [► siu.edu \[pdf\]](#)

R Brooks - IEEE journal of robotics and automation, 1986 - [ieeexplore.ieee.org](#)

... The **robot** must **model** ... each piece must be built in order to **run** the **robot** at all ... solution,

we slice the problem on the basis of **desired** external manifestations of ...

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### A three-dimensional passive-dynamic **walking robot** with two legs and knees

SH Collins, M Wisse, A Ruina - The International Journal of Robotics Research, 2001 - [ijr.sagepub.com](#)

... which tends to constantly control actuation to **force** a system ... we would use trial, error, and **correction** to minimize ... of **angular momentum** about a **vertical** axis. ...

Cited by 270 - Related articles - BL Direct

### A hop towards **running humanoid biped**- [►listory.com](#) (PDF)

S Kajita, T Nagasaki, K Kaneko, K Yokoi, K ... - 2004 IEEE International Conference on Robotics and ... - [ieeexplore.ieee.org](#)

... by-product of this **adjustment**, we obtained smaller touchdown impact ... steady hopping motion more clearly from the **vertical** floor reaction **force** shown in Fig ...

Cited by 44 - Related articles - BL Direct - All 7 versions

### **Adjusting** step length for rough terrain locomotion

JK Hodgins, MN Raibert - IEEE Transactions on Robotics and Automation, 1991 - [ieeexplore.ieee.org](#)

... occurred late in the step, the **adjustment** was made ... roll information was provided by a **vertical** gyroscope ... develop the control algorithms for **adjusting** step length ...

Cited by 138 - Related articles - All 3 versions

### (PDF) [►Stable control of a simulated one-legged \*\*running robot\*\* with hip and leg compliance](#)

M Ahmadi, M Buehler - IEEE Transactions on Robotics and Automation, 1997 - CiteSeer

... to remain closely synchronized with the **vertical** motion to ... spring is massless and the spring **force** is axial ... All the **robot** variables and parameters are dened in ...

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### SCOUT: A simple quadruped that walks, climbs, and runs- [►martinbuehler.net](#) (PDF)

M Buehler, R Battaglia, A Cocosco, G Hawker, ... - 1998 IEEE International Conference on Robotics and ..., 1998 - [ieeexplore.ieee.org](#)

... the rear legs, giving the body enough **vertical** velocity for ... the 7th and final phase, a **torque** is applied ... forward speed during flight (via **adjusting** the impact ...

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### A **running** experiment of **humanoid biped**- [►listory.com](#) (PDF)

T Nagasaki, S Kajita, K Kaneko, K Yokoi, K ... - 2004 IEEE/RSJ International Conference on ... - [ieeexplore.ieee.org](#)

... The **vertical momentum** is calculated considering the compliant elements ... equipped with a 6-axes **force** sensor and ... the total(linear and **angular**) **momentum** for the ...

Cited by 21 - Related articles - All 5 versions

### ... and construction of a series of compact **humanoid** robots and development of biped **walk**

...

T Furuta, T Tawara, Y Okumura, M Shimizu, ... - Robotics and Autonomous Systems, 2001 - Elsevier

... strategy has provisions for real-time **gait adjustment** due to ... initial speed and the kicking **force**  $F_k$  ... of inverted pendulum measured from the **vertical** line,  $q$   $m$  ...

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### A new control method for **walking** robots based on **angular momentum**




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